IN THE CLAIMS:

1. (Currently Amended) A machining device for components, the device comprising:

a multiaxial transport means comprising a multiaxial transport robot with a robot hand end movable based on three or more transport means controllable rotary axes of motion;

a carrier connected to said robot hand end of said multiaxial transport means ~~with~~ for movement of said carrier about said axes of motion of said multiaxial transport means;

an independently movable multiaxial machining unit with a robot hand end having a jointing tool[[s]], said multiaxial machining unit being arranged at and mounted to said carrier for movement of said jointing tool about at least two separate controllable axes of motion relative to said carrier connected said robot arm of said transport means.

2. (Currently Amended) A machining device in accordance with claim 1, wherein the transport means ~~is designed as a~~ multiaxial transport robot has six rotary axes.

3. (Currently Amended) A machining device in accordance with claim [[1]] 2, further comprising:

another independently movable multiaxial machining unit with another robot hand end having another jointing tool, said another multiaxial machining unit being arranged at and mounted to said carrier for movement of said another jointing tool about at least two separate controllable axes of motion relative to said carrier connected at said robot arm of said transport means, wherein the machining units are each designed as multiaxial small robots each with a

robot hand with one of said tools.

4. (Currently Amended) A machining device in accordance with ~~claims 1~~ claim 3, wherein the machining units are arranged on different sides of the carrier.

5. (Currently Amended) A machining device in accordance with claim [[1]] 3, wherein the machining units can be controlled individually.

6. (Currently Amended) A machining device in accordance with claim [[1]] 3, wherein the machining units can be controlled from the transport means.

7. (Previously Presented) A machining device in accordance with claim 1, wherein the carrier is designed as an essentially straight girder.

8. (Currently Amended) A machining device in accordance with claim [[1]] 3, wherein the small robots are designed as six-axis articulated arm robots each for moving the jointing tool relative to the six rotary axes.

9. (Currently Amended) A machining device in accordance with claim [[1]] 3, wherein the machining units are arranged on different sides of the carrier, offset in relation to one another.

10. (Currently Amended) A machining device in accordance with claim 1, wherein each jointing tool is replaceably connected with an associated robot hand of one of the machining units ~~carry said replaceable tools~~.

11. (Canceled).

12. (Currently Amended) A machining device in accordance with claim 1, wherein an additional support is provided for the carrier, said carrier being connected to said additional support by a ball and socket joint.

13. A machining station, comprising:

at least one machining device comprising:

a multiaxial robot transport comprising a multiaxial transport robot with a robot hand end movable based on six transport means controllable rotary axes of motion;

a carrier connected to said robot hand end of said multiaxial robot transport for movement therewith;

a plurality of multiaxial machining units mounted on and carried by said carrier, each of said multiaxial machining units comprising a six-axis articulated arm robot for moving the jointing tool relative to said carrier and having a robot hand end;

a plurality of jointing tools, each robot hand end of said multiaxial machining units being connected to a respective one of said jointing tools.

14. (Currently Amended) A machining station in accordance with claim 13, further comprising:

a station frame, wherein ~~each~~ said machining device ~~(s) (5)~~ is arranged at said station frame.

15. (Currently Amended) A machining station in accordance with claim 13, wherein ~~each~~ said machining device ~~(s) (5)~~ is designed as a portal robot/portal robots.

16. (Currently Amended) A method of machining ~~said cubic~~ components having structural features defining an interior space, ~~by means of a multiaxial transport means and at least one said tool,~~ the method comprising the steps of:

providing a multiaxial transport robot with a robot hand end movable based on three or more transport controllable rotary axes of motion;

providing a carrier connected to the robot hand for movement about the axes of motion of the multiaxial transport robot;

providing a plurality of independently movable multiaxial machining units arranged at and mounted to the carrier, each of the multiaxial machining units having a robot hand end having a tool, with at least one tool being a jointing tool, the multiaxial machining unit being

for movement of the tool about at least two separate controllable axes of motion relative to the carrier; and further comprising the steps of:

employing the transport ~~means~~ robot for introducing ~~at least one~~ the carrier with ~~one or more~~ the multiaxial machining units into the interior space of the component, wherein the machining units carry out machining operations, including at least one of said machining units carrying out jointing, on the inside of the component in the interior space.

17. (Currently Amended) A method in accordance with claim 16, wherein:

the transport means robot has six rotary axes;

the independently movable multiaxial machining units are each six-axis articulated arm robots each for moving the jointing tool relative to the six rotary axes;

a plurality of the tools are jointing tools including one or more of clamping tools, welding tools and bonding tools and;

the component is clamped on the inside by one or more said machining units and is machined including being jointed by said other machining units.

18. (Previously Presented) A method in accordance with claim 16, wherein the carrier with the machining units is introduced through an opening into the component.

19. (Currently Amended) A method in accordance with claims 16, wherein the carrier with the machining units is additionally supported in the working position by an additional

support ~~means~~, said carrier being connected to said additional support by a ball and socket joint.

20. (New) A machining station in accordance with claim 13, wherein one or more of said multiaxial machining units are for clamping the workpiece from at least one of the inside and the outside of an interior space defined by the workpiece.

21. (New) A method in accordance with claim 16, wherein wherein one or more of said multiaxial machining units are for clamping the workpiece from at least one of the inside and the outside of an interior space defined by the workpiece.